

## Patent Abstracts of Japan

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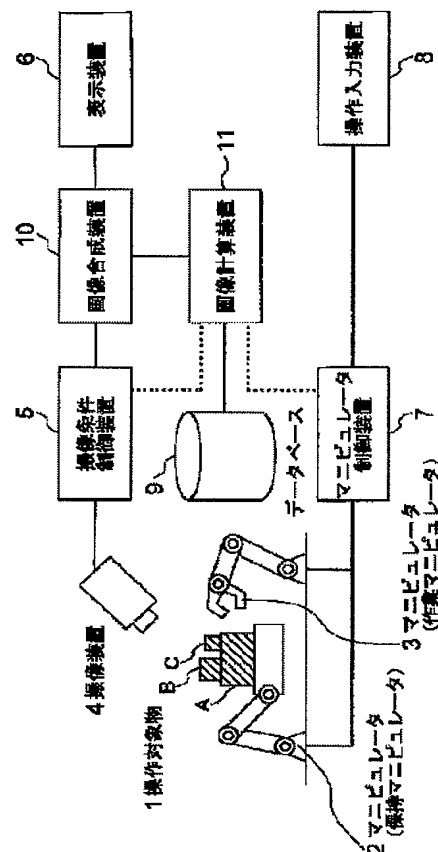
APPLICATION DATE : 30-09-99  
APPLICATION NUMBER : 11277847

APPLICANT : JAPAN SCIENCE & TECHNOLOGY  
CORP;

INVENTOR : SATO TOMOMASA;

INT.CL. : G05B 19/19 B25J 13/08

TITLE : METHOD AND DEVICE FOR  
CONTROLLING MANIPULATOR



ABSTRACT : PROBLEM TO BE SOLVED: To provide a manipulator control method capable of efficiently assembling or arranging an object with high accuracy, when performing work which cannot be directly manually executed, such as manipulation of a fine object under a microscope while using a manipulator.

SOLUTION: Concerning the manipulator control method for moving or working a manipulation object, it is calculated how the image of the manipulation object in an ideal state after manipulating work is picked up by an image-pickup device based on a data base recording the state of the manipulation object and the ideal state after the manipulating work, the image picked up with the image-pickup device and an image based on the same calculation are displayed while being overlapped on the same picture, and the manipulator is controlled so as to match the real image and the calculated image.

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# DELPHION

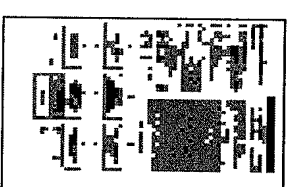
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SATO TOMOMASA;****Assignee:** **JAPAN SCIENCE & TECHNOLOGY CORP**  
[News, Profiles, Stocks and More about this company](#)**Published / Filed:** **2001-04-13 / 1999-09-30****Application Number:** **JP1999000277847****IPC Code:**Advanced: **B25J 13/08; G02B 21/32; G05B 19/19;**  
Core: more...  
IPC-7: **B25J 13/08; G05B 19/19;****Priority Number:** **1999-09-30 JP1999000277847****Abstract:**

**PROBLEM TO BE SOLVED:** To provide a manipulator control method capable of efficiently assembling or arranging an object with high accuracy, when performing work which cannot be directly manually executed, such as manipulation of a fine object under a microscope while using a manipulator.

**SOLUTION:** Concerning the manipulator control method for moving or working a manipulation object, it is calculated how the image of the manipulation object in an ideal state after manipulating work is picked up by an image-pickup device based on a data base recording the state of the manipulation object and the ideal state

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after the manipulating work, the image picked up with the image-pickup device and an image based on the same calculation are displayed while being overlapped on the same picture, and the manipulator is controlled so as to match the real image and the calculated image.

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 INPADOC

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 Family:

| Buy PDF                             | Publication    | Pub. Date  | Filed      | Title   |
|-------------------------------------|----------------|------------|------------|---|
| <input checked="" type="checkbox"/> | ITW0468055B    | 2001-12-11 | 2000-08-05 | METHOD AND DEVICE FOR CONTROLLING MANIPULATOR |
| <input checked="" type="checkbox"/> | JP2001100821A2 | 2001-04-13 | 1999-09-30 | METHOD AND DEVICE FOR CONTROLLING MANIPULATOR |
| 2 family members shown above        |                |            |            |   |

 Other Abstract Info:

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